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<u>L9</u>	<u>L9</u>	15 and ((vector) and (damp3 adj ratio))	0	<u>L9</u>
<u>L8</u>	<u>L8</u>	15 and ((frequency adj vector) and (damp3 adj ratio))	0	<u>L8</u>
<u>L7</u>	<u>L7</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and ((time adj delay adj control)) and (natural adj3 frequency adj vector)	1	<u>L7</u>
<u>L6</u>	<u>L6</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and ((time adj delay adj control)) and (frequency adj3 vector)	1	<u>L6</u>
<u>L5</u>	<u>L5</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and ((time adj delay))	41	<u>L5</u>
<u>L4</u>	<u>L4</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and (tdc or (time adj delay adj control))	1	<u>L4</u>
<u>L3</u>	<u>L3</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and (tdc or (time adj delay adj control)) and (frequency adj3 vector)	1	<u>L3</u>
<u>L2</u>	<u>L2</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and (tdc or (time adj delay adj control)) and (frequency adj vector)	1	<u>L2</u>
<u>L1</u>	<u>L1</u>	(tun\$3 adj3 pid adj controller) and (closed adj loop) and (tdc or (time adj delay adj control)) and (natural adj3 frequency adj vector)	1	<u>L1</u>

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- 1. A model reference observer for time-delay control and its application to robot trajectory control**

Chang, P.H.; Lee, J.W.;

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## 1. Analysis for charged spacers in FED

Choi, Y.S.; Cha, S.N.; Jung, S.Y.; Kim, J.W.; Jung, J.E.; Kim, J.M.;

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